

AMENDMENTS TO THE CLAIMS

This listing of claims will replace all prior versions and listings of claims in the application:

LISTING OF CLAIMS:

1. (currently amended): A lower half body module of a bipedal walking robot comprising:

a base;

a right foot and a left foot;

a plurality of passive joints which are respectively provided on said base, said right foot and said left foot; and

parallel link mechanism portions which are respectively provided between said passive joint provided on said base and said passive joints provided on said right foot and between said passive joint provided on said base and said passive joints provided on said left foot, and further comprising as said passive joints:

base side passive joints having overturned U-shaped base side upper couplings fixed to said base, overturned U-shaped base side lower couplings fixed to ends of said linear motion links respectively and connecting rotating portions which orthogonally and rotatably connect said base side upper coupling with said base side lower coupling; ~~and~~

foot side passive joints having overturned U-shaped foot side upper couplings fixed to the other ends of said linear motion links respectively, overturned U-shaped foot side lower couplings rotatably fixed to said feet respectively, and connecting rotating portions which respectively orthogonally and rotatably connect said foot side upper coupling with said foot side lower coupling; and

the parallel link mechanism portion (1a) of the right leg and the parallel link mechanism portion (1b) of the left leg provided on the both sides of the base (2) respectively so as to be symmetrically to the center thereof.

2. (original): A lower half body module of a bipedal walking robot according to Claim 1, wherein the three sets of said parallel link mechanism portions are respectively provided between said base and said right foot and between said base and said left foot.

3. (original): A lower half body module of a bipedal walking robot according to any one of Claims 1 or 2, wherein said parallel link mechanism portions respectively have six degrees of freedom.

4. (currently amended): A lower half body module of a bipedal walking robot according to any one of Claims 1 ~~to 3~~ or 2, comprising a plurality of telescopic linear motion links which are provided between said base and said right foot and between said base and said left foot via said passive joints as links of said parallel link mechanism portions.

5. (currently amended): A lower half body module of a bipedal walking robot according to ~~any one of Claims 1 to 4~~ Claim 4, wherein the links of said parallel link mechanism portions respectively include a linear motion type actuator as an actuator.

6. (original): A lower half body module of a bipedal walking robot according to Claim 5, wherein said linear motion type actuator is provided at said base side of said linear motion link.

7. (canceled).